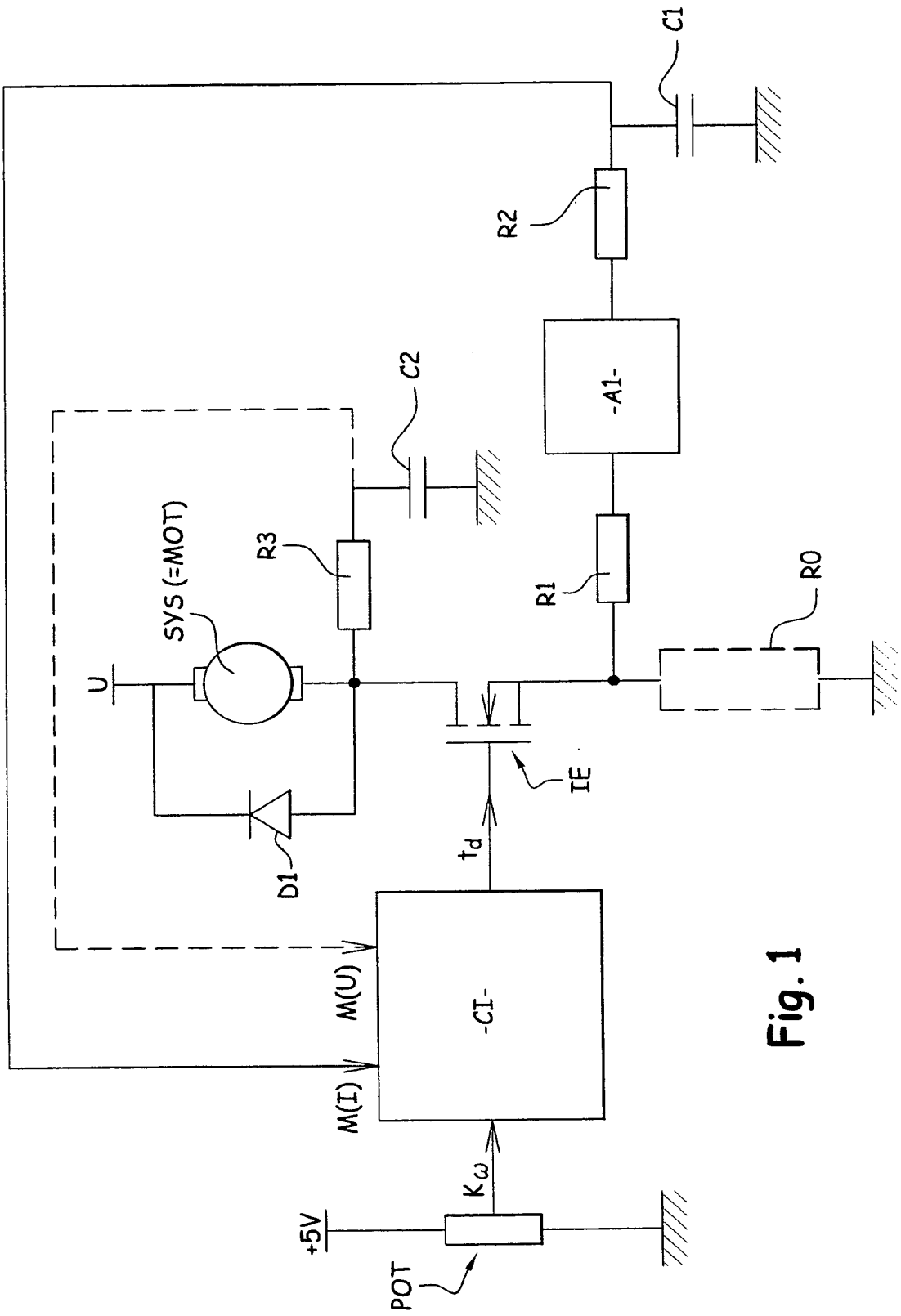
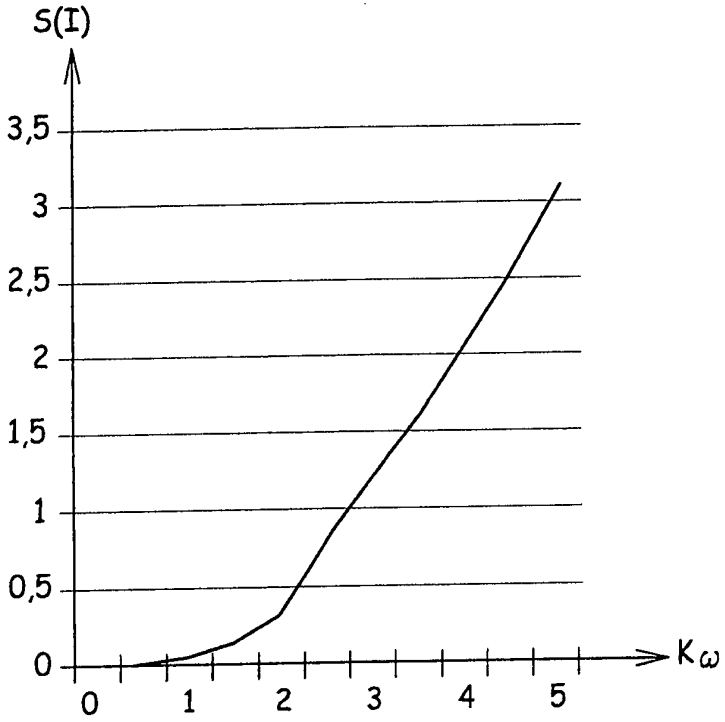
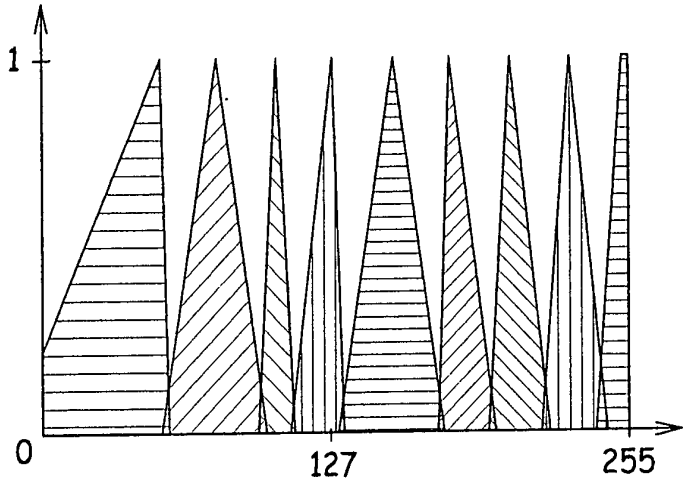


Fig. 1





+

```
If Kω is X0, then S(I) is Y0
If Kω is X1, then S(I) is Y1
If Kω is X2, then S(I) is Y2
      . . . . .
If Kω is X9, then S(I) is Y9
```

Fig. 2

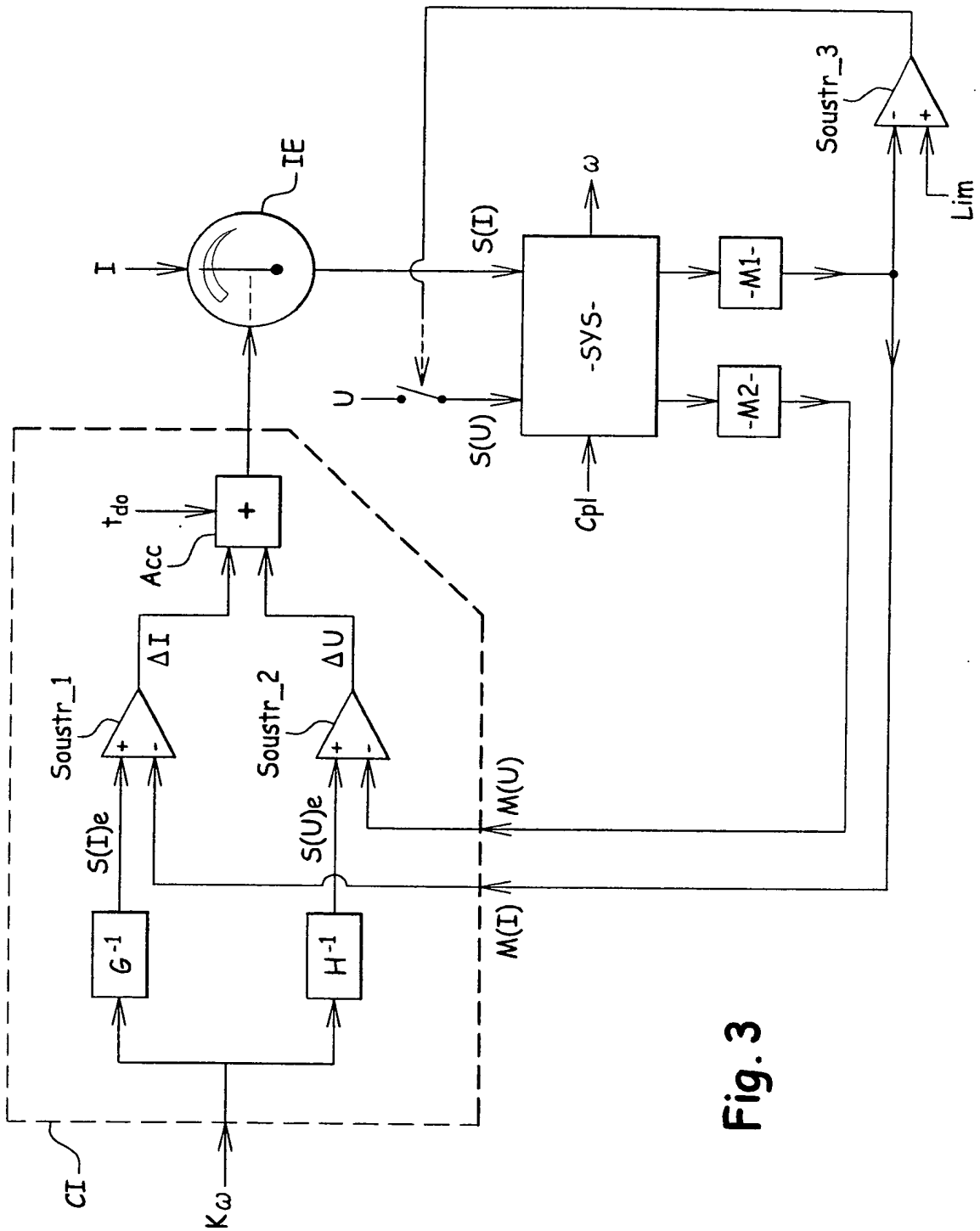

IE
I
S(I)
ω
Soustr_3
Lim
-SYS-
-M1-
-M2-
U
S(U)
Cpl
t_{do}
Acc
+
ΔI
ΔU
Soustr_1
Soustr_2
S(I)e
S(U)e
M(U)
M(I)
G^{-1}
H^{-1}
CI
K_ω

Fig. 3